analysis all #4459-0513-14

analysis all #4459-0513-14

1. 准备
2. plot computed_path*.txt
    1. dvr_0513_rs_1_left
    2. dvr_0513_rs_1_right
    3. dvr_0513_mode10_2_left
    4. dvr_0513_mode10_1_right

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1. 准备

TS: 2c0ad6575fbbd4bc69bc22704fb27838276aaa5f【0513】

TS: d141d5b02b4172c282476a9f2049934ffd7c70eb【0514】

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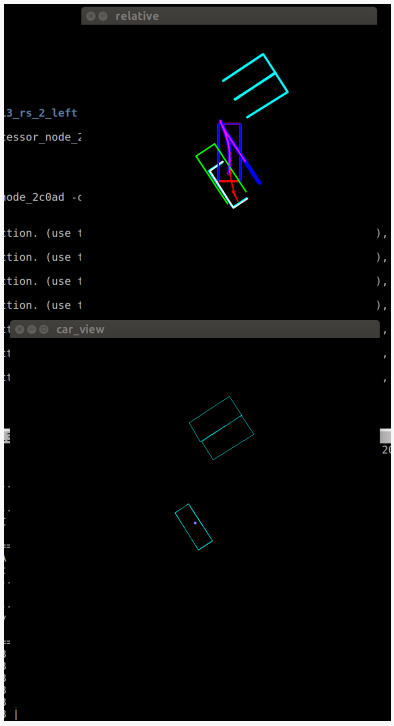
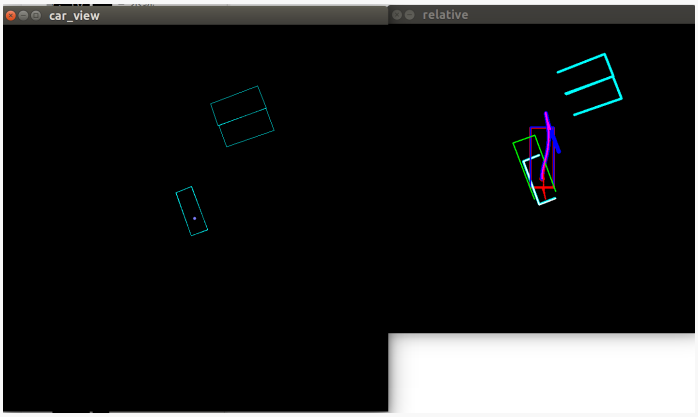
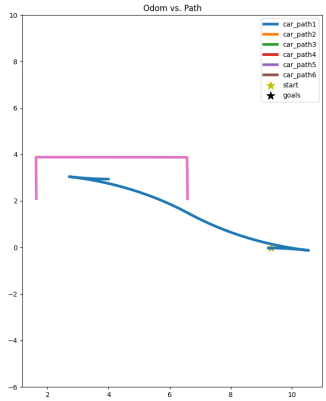
2. plot computed_path*.txt

1. dvr_0513_rs_1_left

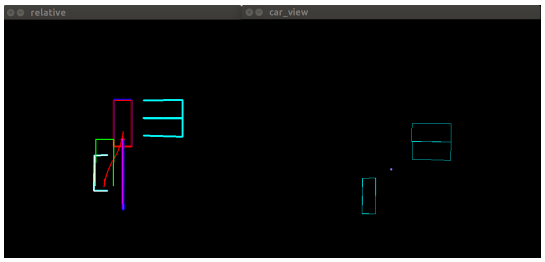


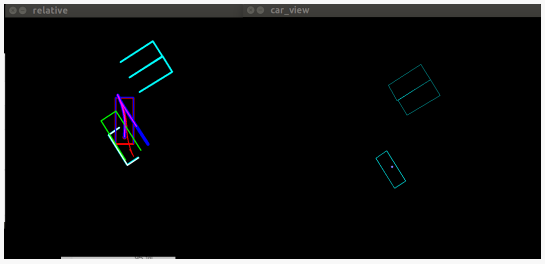




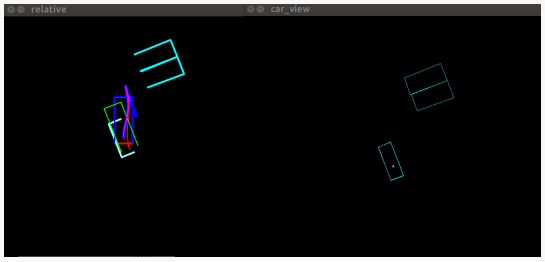
compare 0514

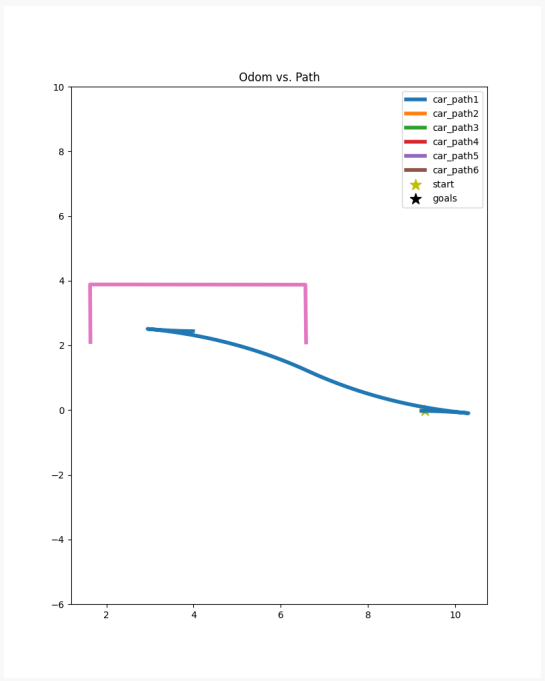
0514


relative
car_view

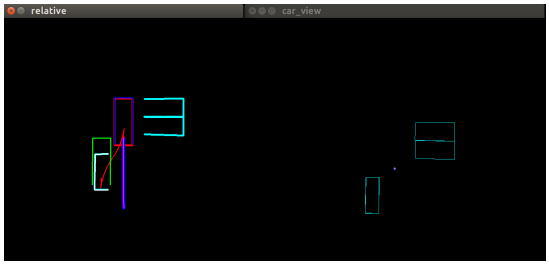

relative
car_view

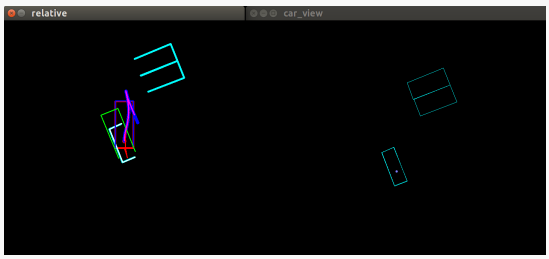
relative
car_view

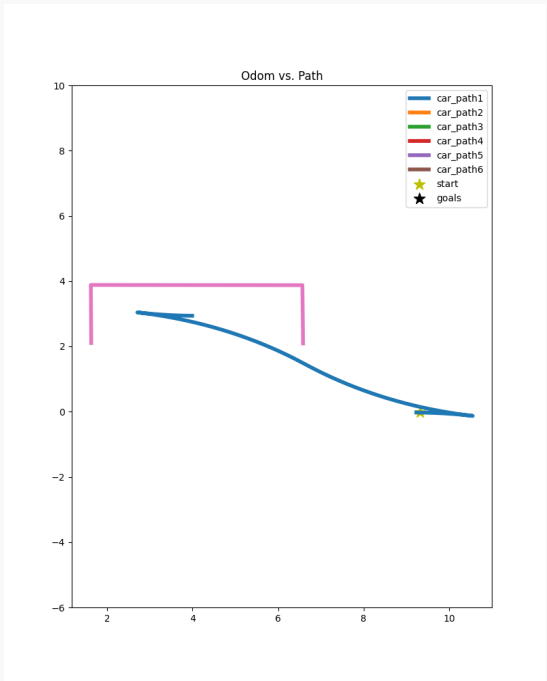

relative
car_view

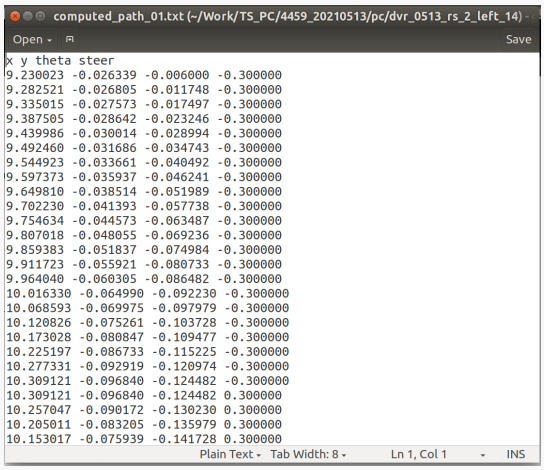
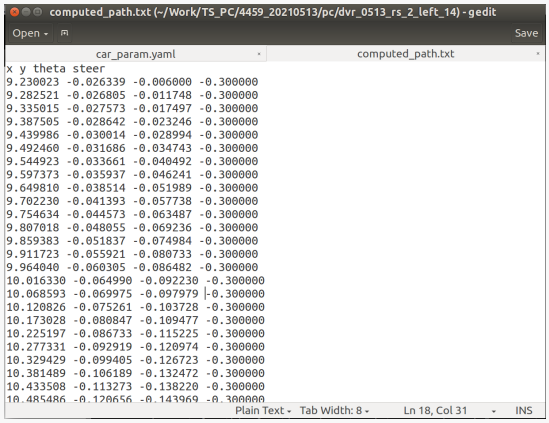
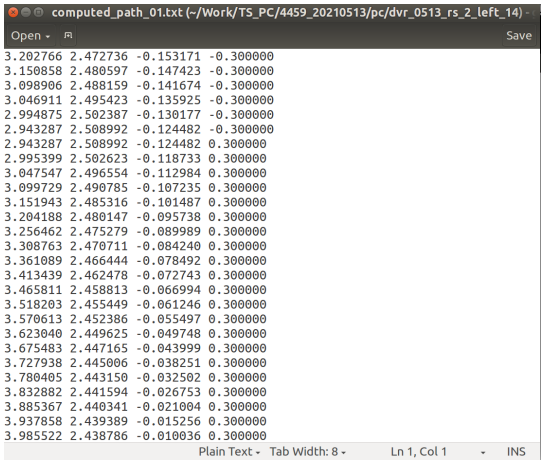
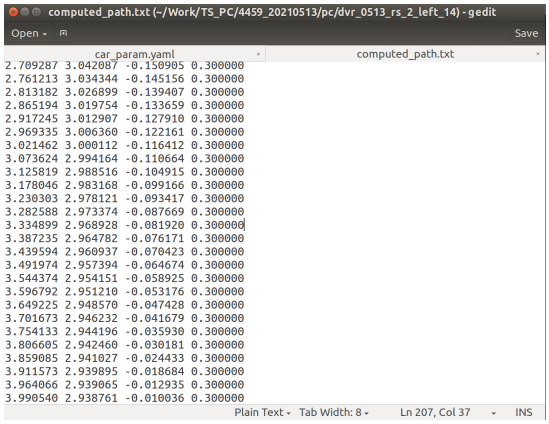

Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals
10
8
6
4
2
0
−2
−4
−6
2
4
6
8
10

0513

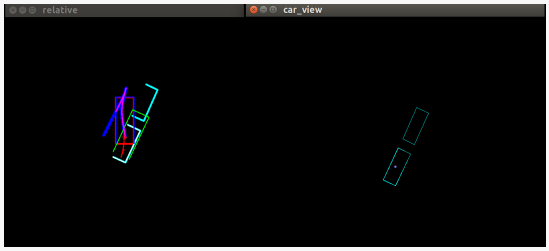

relative
car_view

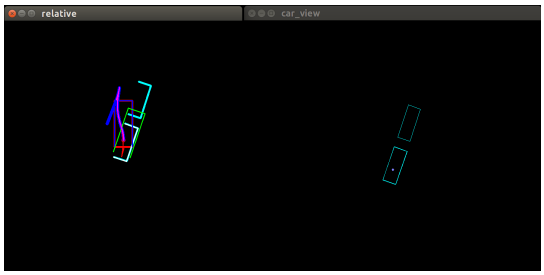

relative
car_view

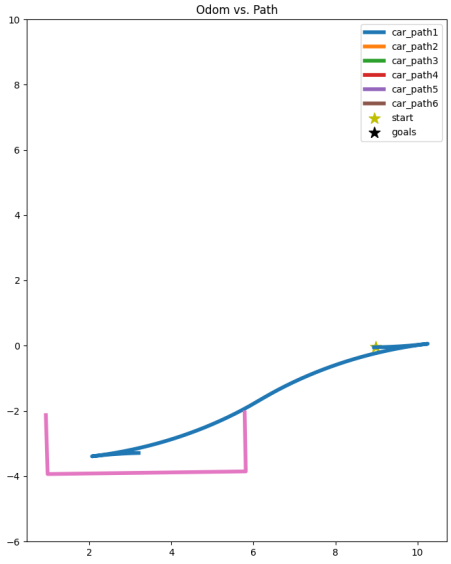

Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals
10
8
6
4
2
0
−2
−4
−6
2
4
6
8
10

0514	0513
	
	

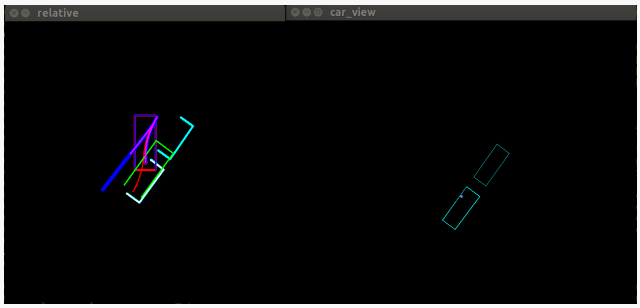
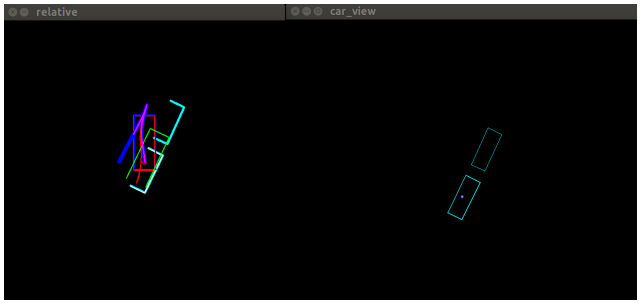
2. dvr_0513_rs_1_right



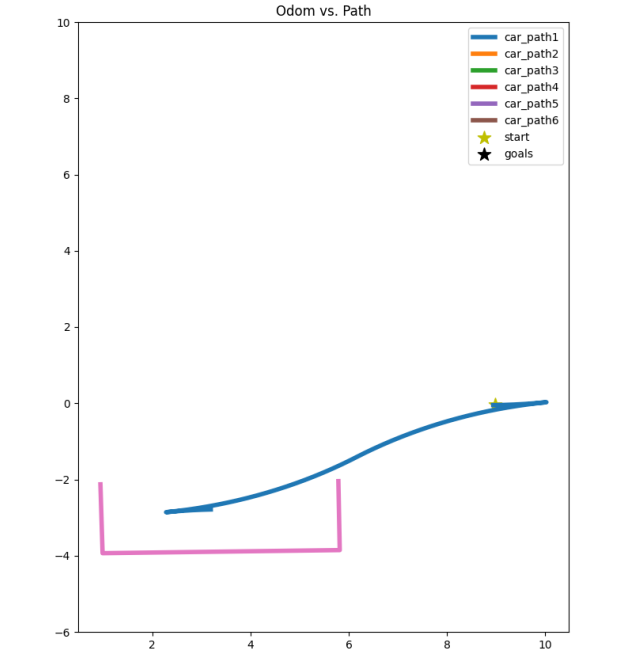




compare 0514

0514	0513
relative car_view	
 relative car_view	
 relative car_view	
relative car_view	

0514



computed_path_01.txt (~/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_1_righ

Open Save

```
x y theta steer
8.940826 -0.049197 0.009714 0.300000
8.993322 -0.048536 0.015463 0.300000
9.045814 -0.047573 0.021211 0.300000
9.098298 -0.046309 0.026960 0.300000
9.150775 -0.044743 0.032709 0.300000
9.203241 -0.042875 0.038458 0.300000
9.255696 -0.040706 0.044206 0.300000
9.308138 -0.038235 0.049955 0.300000
9.360565 -0.035463 0.055704 0.300000
9.412974 -0.032389 0.061453 0.300000
9.465366 -0.029014 0.067201 0.300000
9.517737 -0.025339 0.072950 0.300000
9.570086 -0.021362 0.078699 0.300000
9.622412 -0.017084 0.084447 0.300000
9.674711 -0.012505 0.090196 0.300000
9.726984 -0.007626 0.095945 0.300000
9.779228 -0.002446 0.101694 0.300000
9.831441 0.003033 0.107442 0.300000
9.883622 0.008813 0.113191 0.300000
9.935768 0.014893 0.118940 0.300000
9.987880 0.021272 0.124689 0.300000
10.023583 0.025819 0.128630 0.300000
10.023583 0.025819 0.128630 -0.300000
9.971538 0.018935 0.134378 -0.300000
9.919531 0.011752 0.140127 -0.300000
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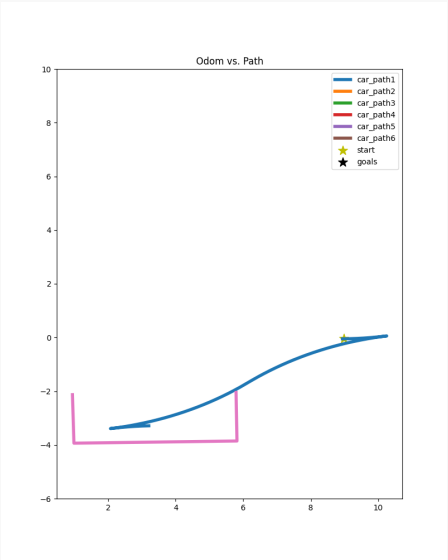
Plain Text Tab Width: 8 Ln 9, Col 37 INS

0513



computed_path_01_13.txt (~/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_1_

Open Save

```
x y theta steer
8.940826 -0.049197 0.009714 0.300000
8.993322 -0.048536 0.015463 0.300000
9.045814 -0.047573 0.021211 0.300000
9.098298 -0.046309 0.026960 0.300000
9.150775 -0.044743 0.032709 0.300000
9.203241 -0.042875 0.038458 0.300000
9.255696 -0.040706 0.044206 0.300000
9.308138 -0.038235 0.049955 0.300000
9.360565 -0.035463 0.055704 0.300000
9.412974 -0.032389 0.061453 0.300000
9.465366 -0.029014 0.067201 0.300000
9.517737 -0.025339 0.072950 0.300000
9.570086 -0.021362 0.078699 0.300000
9.622412 -0.017084 0.084447 0.300000
9.674711 -0.012505 0.090196 0.300000
9.726984 -0.007626 0.095945 0.300000
9.779228 -0.002446 0.101694 0.300000
9.831441 0.003033 0.107442 0.300000
9.883622 0.008813 0.113191 0.300000
9.935768 0.014893 0.118940 0.300000
9.987880 0.021272 0.124689 0.300000
10.039953 0.027951 0.130437 0.300000
10.091987 0.034929 0.136186 0.300000
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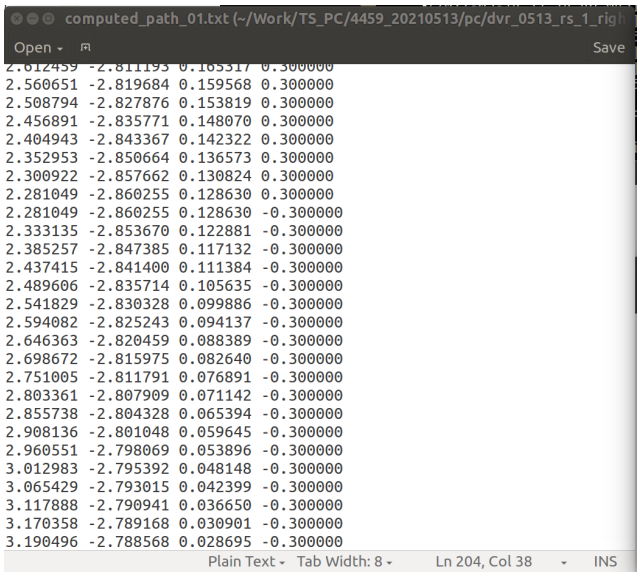
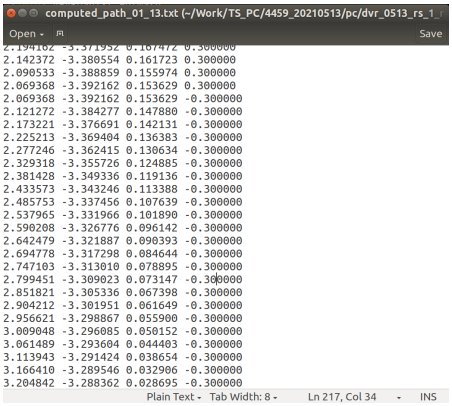
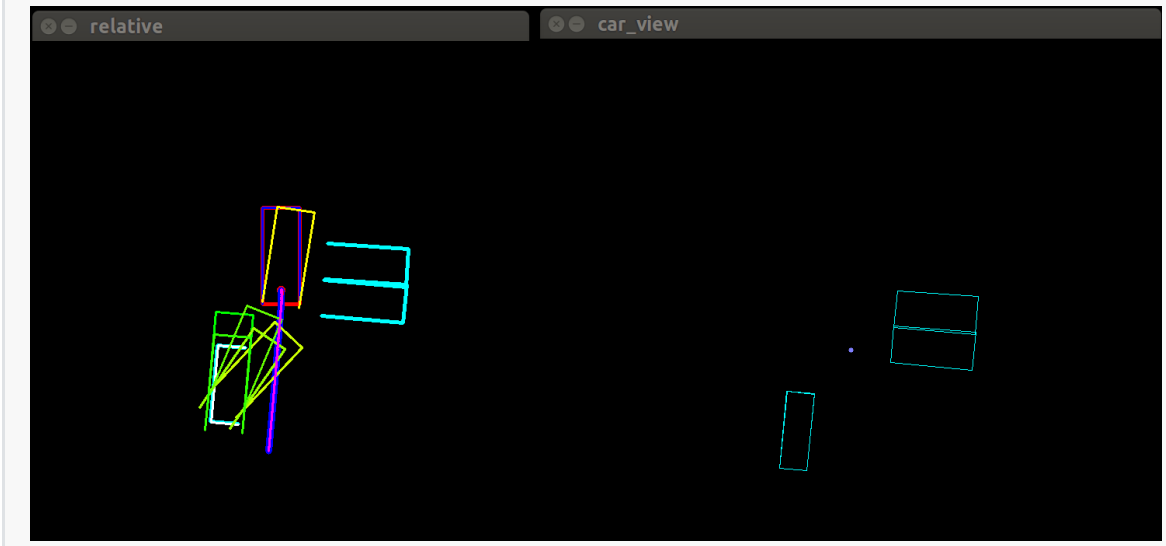
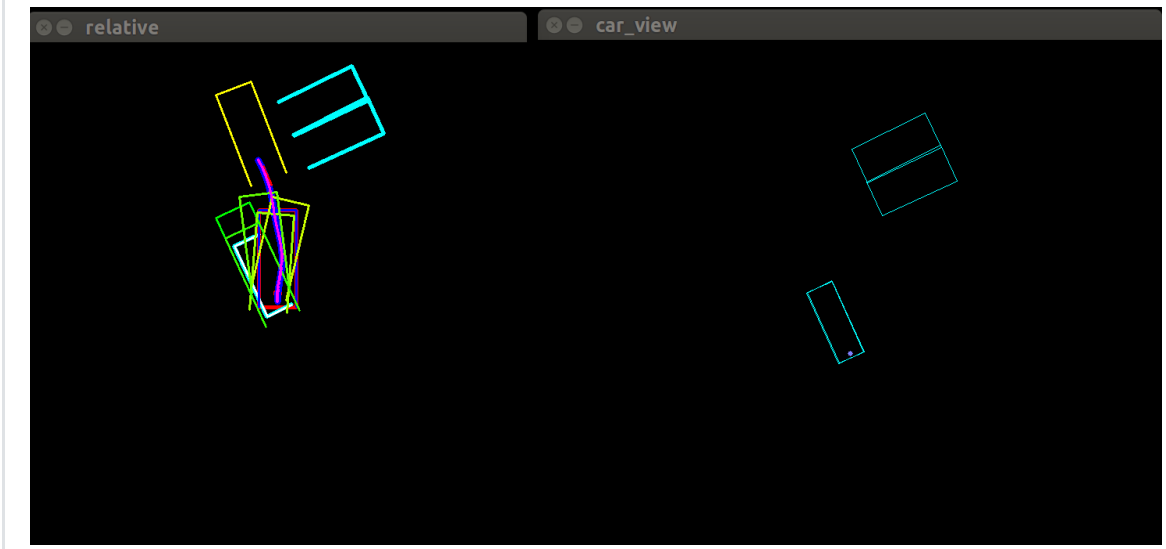
```

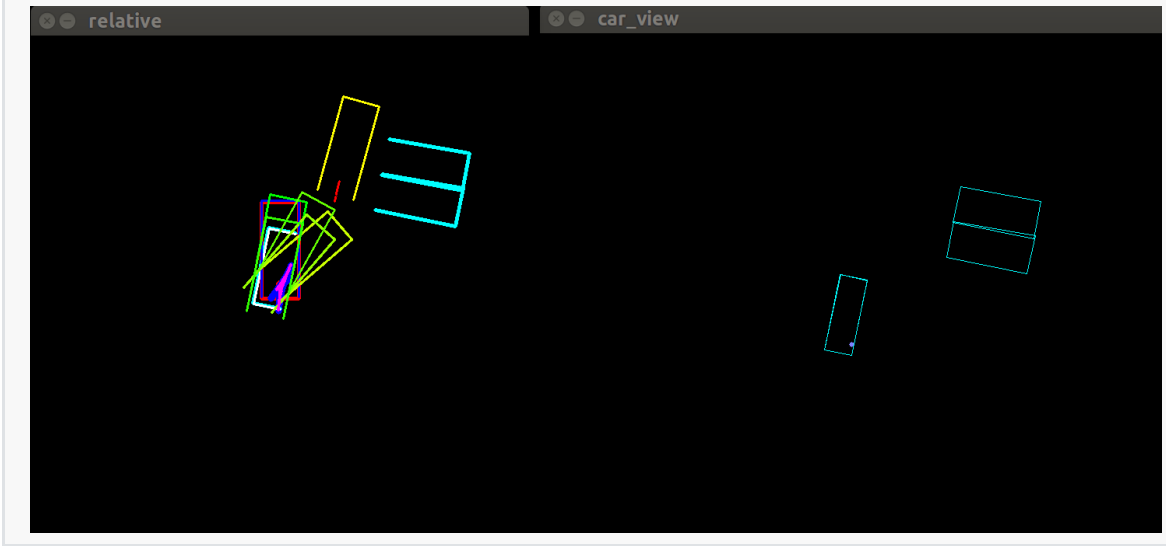
Plain Text Tab Width: 8 Ln 11, Col 12 INS

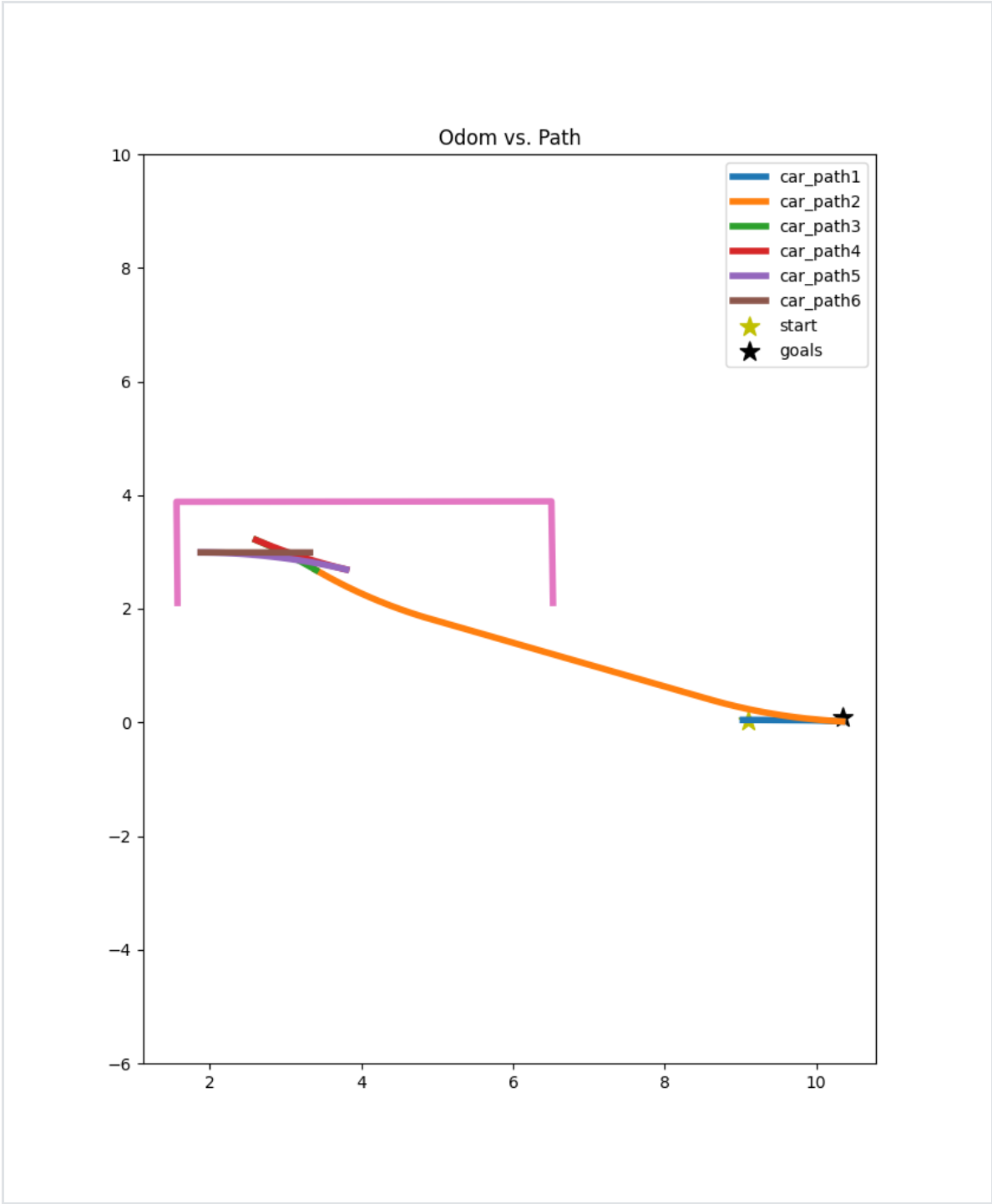
0514	0513
	

3. dvr_0513_mode10_2_left


relative
car_view

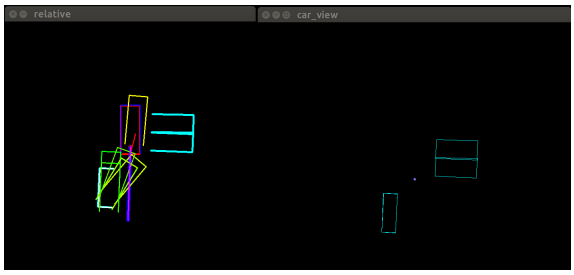

relative
car_view

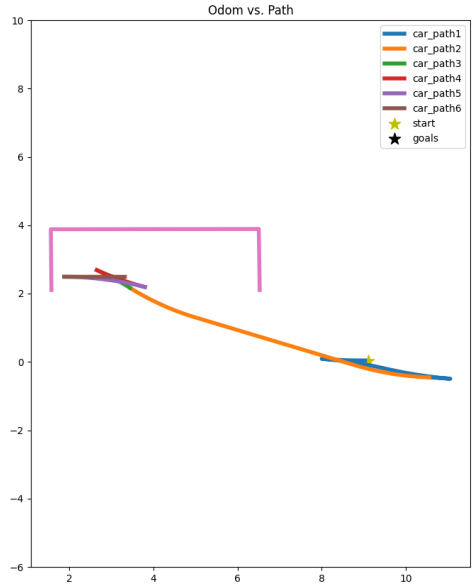

relative
car_view

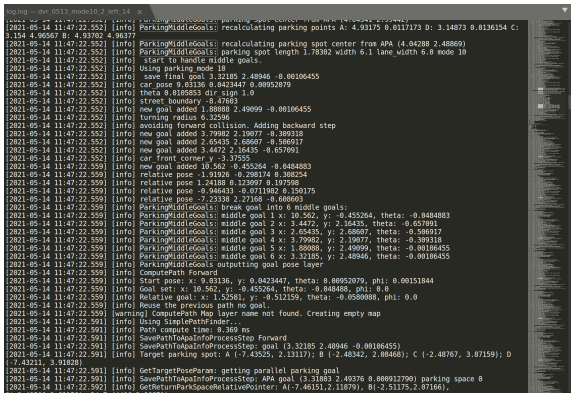


compare 0514

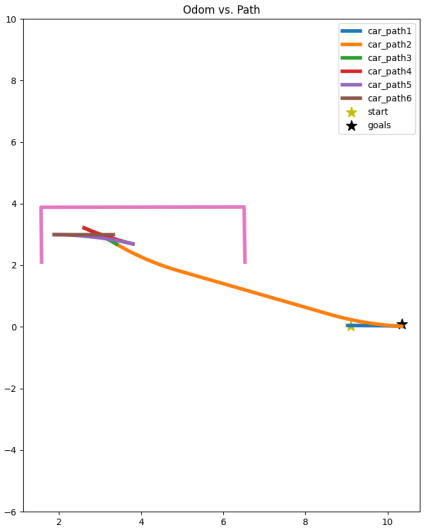
0514

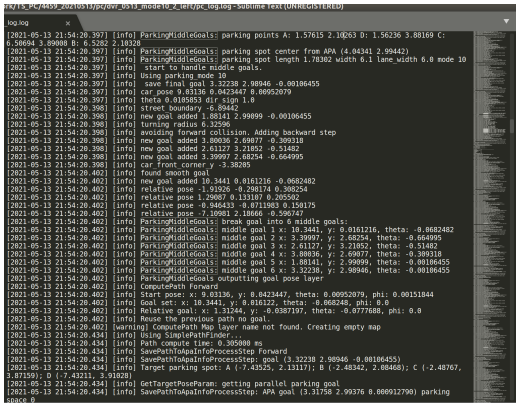

relative
car_view


Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals



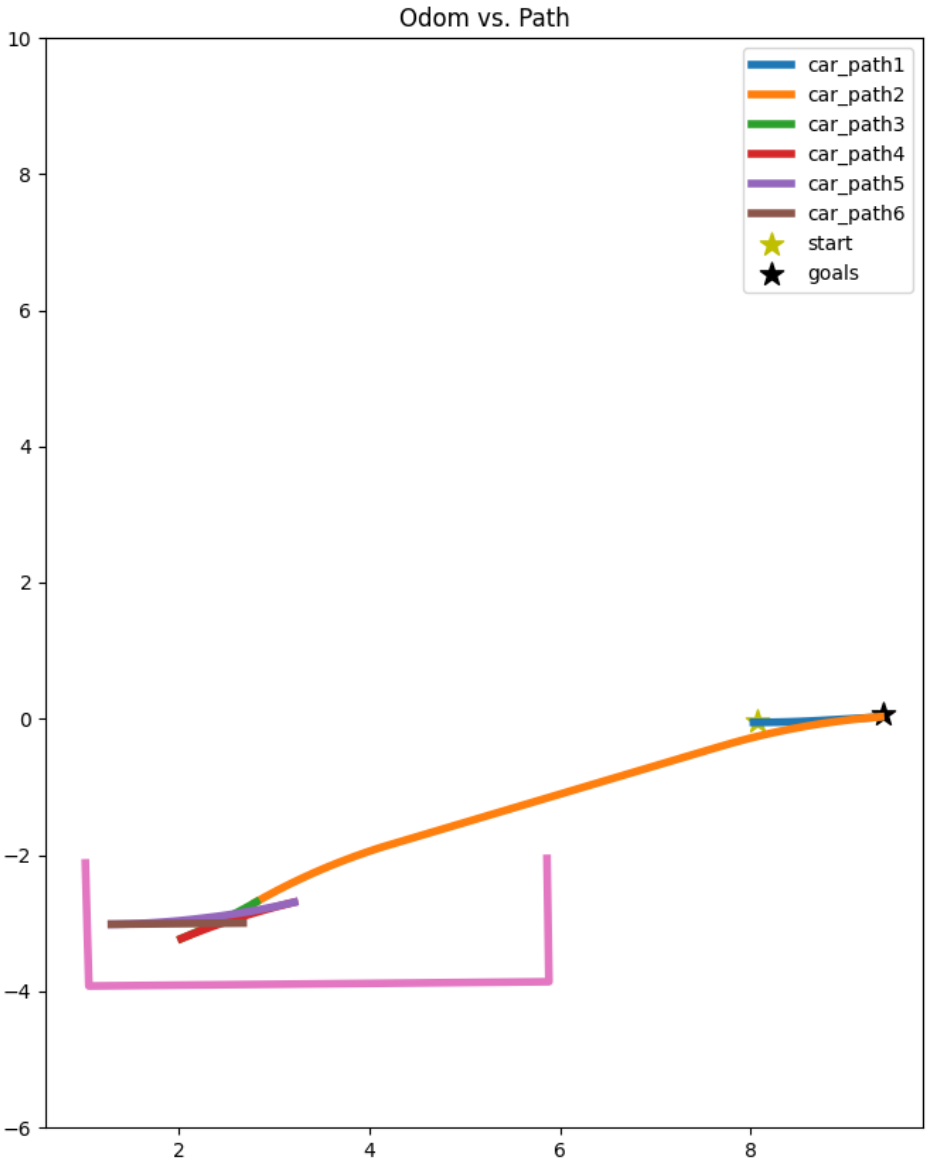
0513


Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals

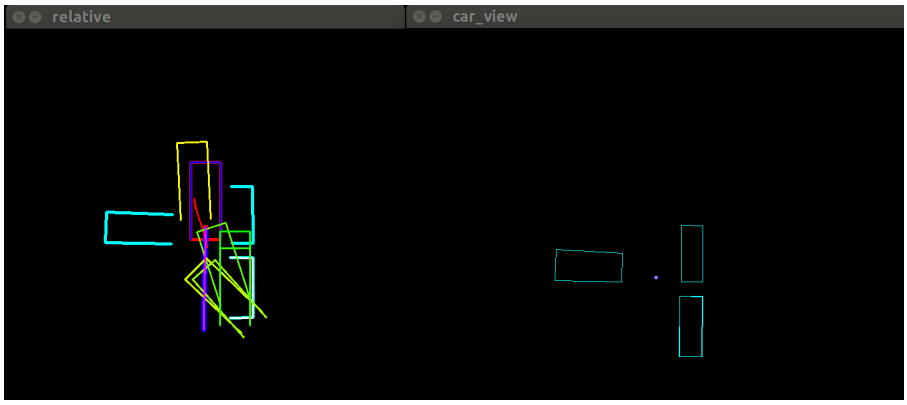
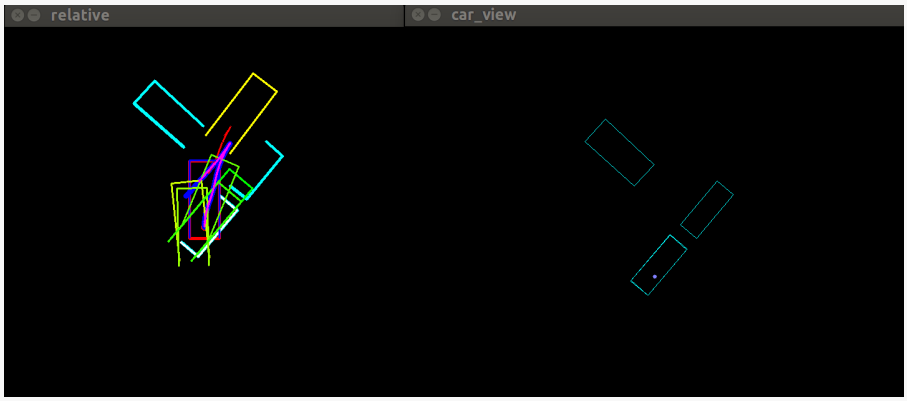


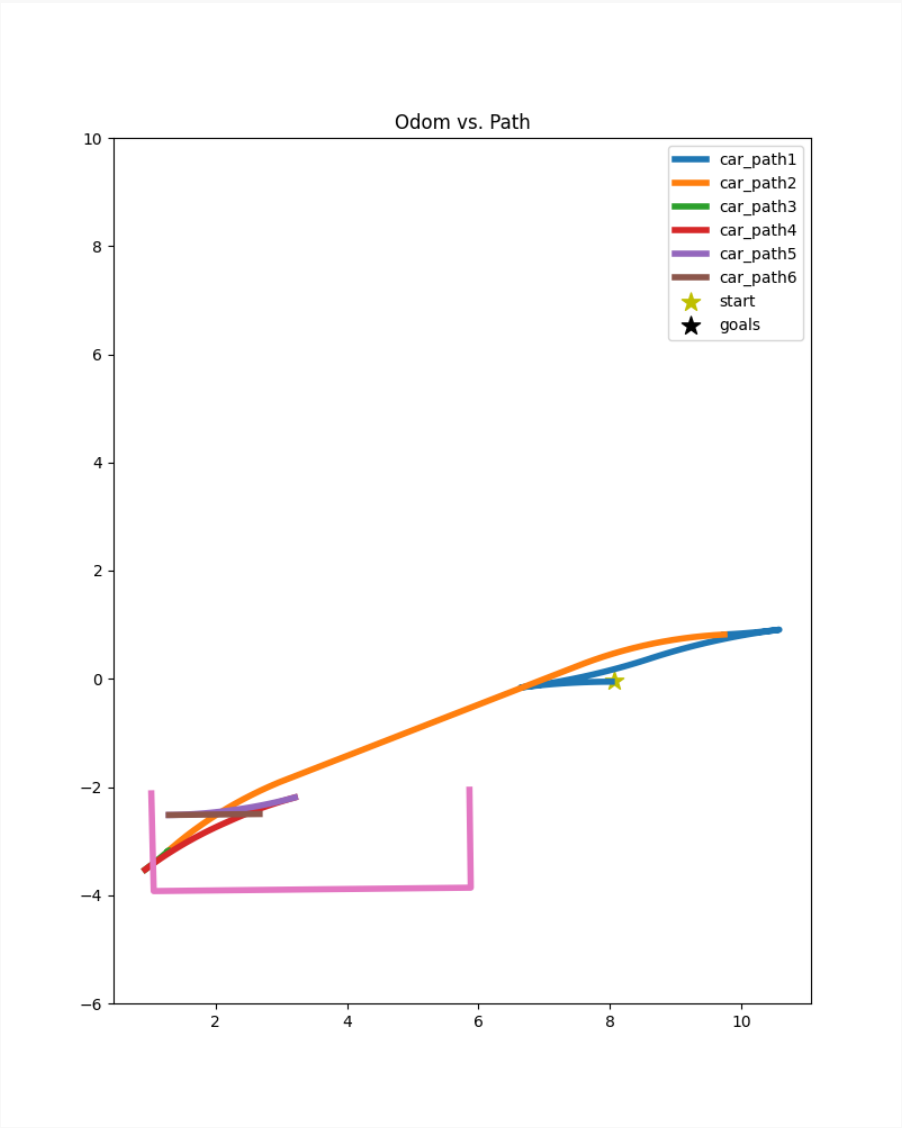
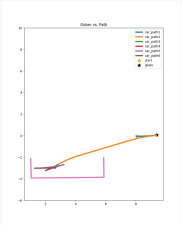
4. dvr_0513_mode10_1_right

relative
car_view

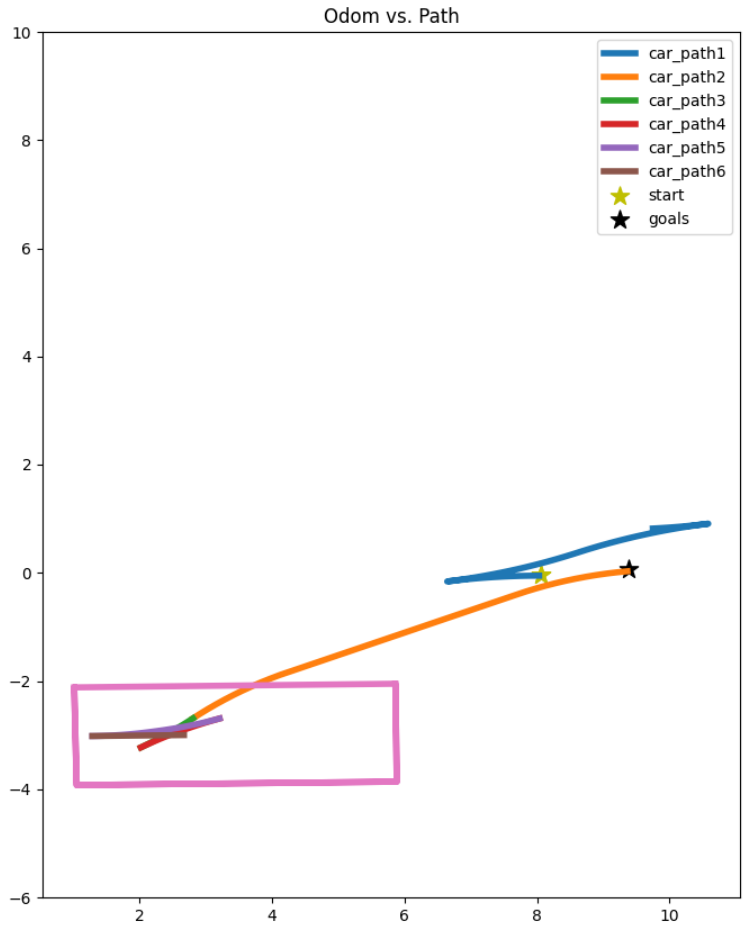
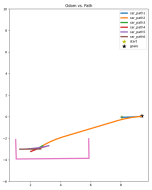
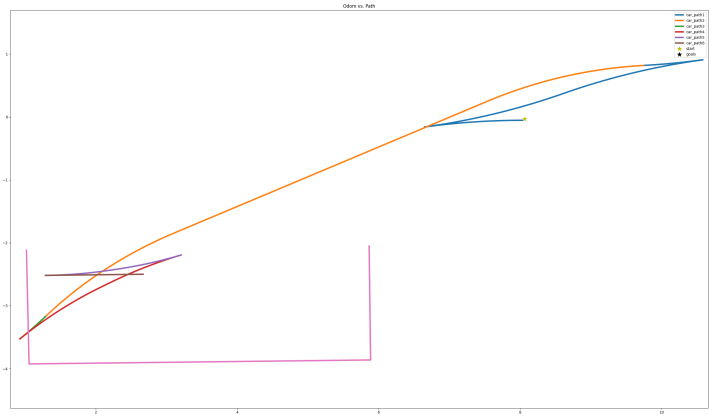

Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals
10
8
6
4
2
0
−2
−4
−6
2
4
6
8

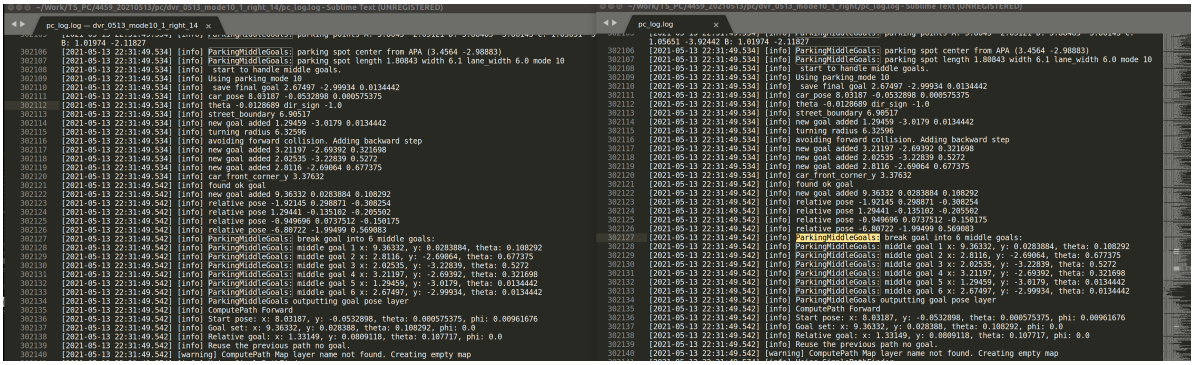
compare 0514

0514	0513
	
	

0514	0513
	

Odom vs. Path
car_path1
car_path2
car_path3
car_path4
car_path5
car_path6
start
goals
10
8
6
4
2
0
−2
−4
−6
2
4
6
8
10

0514	0513
 Odom vs. Path car_path1 car_path2 car_path3 car_path4 car_path5 car_path6 start goals 10 8 6 4 2 0 −2 −4 −6 2 4 6 8 10	
	



~/Work/T5_PC/4459_20210513/pc/dvr_0513_mode10_1_right_14/pc_log.log - Sublime Text (UNREGISTERED)

pc_log.log — dvr_0513_mode10_1_right_14

```
302106  [2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot center from APA (3.4564 -2.98883)
302107  [2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot length 1.80843 width 6.1 lane_width 6.0 mode 10
302108  [2021-05-13 22:31:49.534] [info]  start to handle middle goals.
302109  [2021-05-13 22:31:49.534] [info] Using parking mode 10
302110  [2021-05-13 22:31:49.534] [info]  save final goal 2.67497 -2.99934 0.0134442
302111  [2021-05-13 22:31:49.534] [info] car_pose 8.03187 -0.0532898 0.000575375
302112  [2021-05-13 22:31:49.534] [info] theta -0.0128689 dir sign -1.0
302113  [2021-05-13 22:31:49.534] [info] street_boundary 6.90517
302114  [2021-05-13 22:31:49.534] [info] new goal added 1.29459 -3.0179 0.0134442
302115  [2021-05-13 22:31:49.534] [info] turning radius 6.32596
302116  [2021-05-13 22:31:49.534] [info] avoiding forward collision. Adding backward step
302117  [2021-05-13 22:31:49.534] [info] new goal added 3.21197 -2.69392 0.321698
302118  [2021-05-13 22:31:49.534] [info] new goal added 2.02535 -3.22839 0.5272
302119  [2021-05-13 22:31:49.534] [info] new goal added 2.8116 -2.69064 0.677375
302120  [2021-05-13 22:31:49.534] [info] car front corner_y 3.37632
302121  [2021-05-13 22:31:49.542] [info] found ok goal
302122  [2021-05-13 22:31:49.542] [info] new goal added 9.36332 0.0283884 0.108292
302123  [2021-05-13 22:31:49.542] [info] relative pose -1.92145 0.298871 -0.308254
302124  [2021-05-13 22:31:49.542] [info] relative pose 1.29441 -0.135102 -0.205502
302125  [2021-05-13 22:31:49.542] [info] relative pose -0.949696 0.0737512 -0.150175
302126  [2021-05-13 22:31:49.542] [info] relative pose -6.80722 -1.99499 0.569083
302127  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: break goal into 6 middle goals:
302128  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 1 x: 9.36332, y: 0.0283884, theta: 0.108292
302129  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 2 x: 2.8116, y: -2.69064, theta: 0.677375
302130  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 3 x: 2.02535, y: -3.22839, theta: 0.5272
302131  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 4 x: 3.21197, y: -2.69392, theta: 0.321698
302132  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 5 x: 1.29459, y: -3.0179, theta: 0.0134442
302133  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 6 x: 2.67497, y: -2.99934, theta: 0.0134442
302134  [2021-05-13 22:31:49.542] [info] ParkingMiddleGoals outputting goal pose layer
302135  [2021-05-13 22:31:49.542] [info] ComputePath Forward
302136  [2021-05-13 22:31:49.542] [info] Start pose: x: 8.03187, y: -0.0532898, theta: 0.000575375, phi: 0.00961676
302137  [2021-05-13 22:31:49.542] [info] Goal set: x: 9.36332, y: 0.028388, theta: 0.108292, phi: 0.0
302138  [2021-05-13 22:31:49.542] [info] Relative goal: x: 1.33149, y: 0.0809118, theta: 0.107717, phi: 0.0
302139  [2021-05-13 22:31:49.542] [info] Reuse the previous path no goal.
302140  [2021-05-13 22:31:49.542] [warning] ComputePath Map layer name not found. Creating empty map
```